

FIG. 1

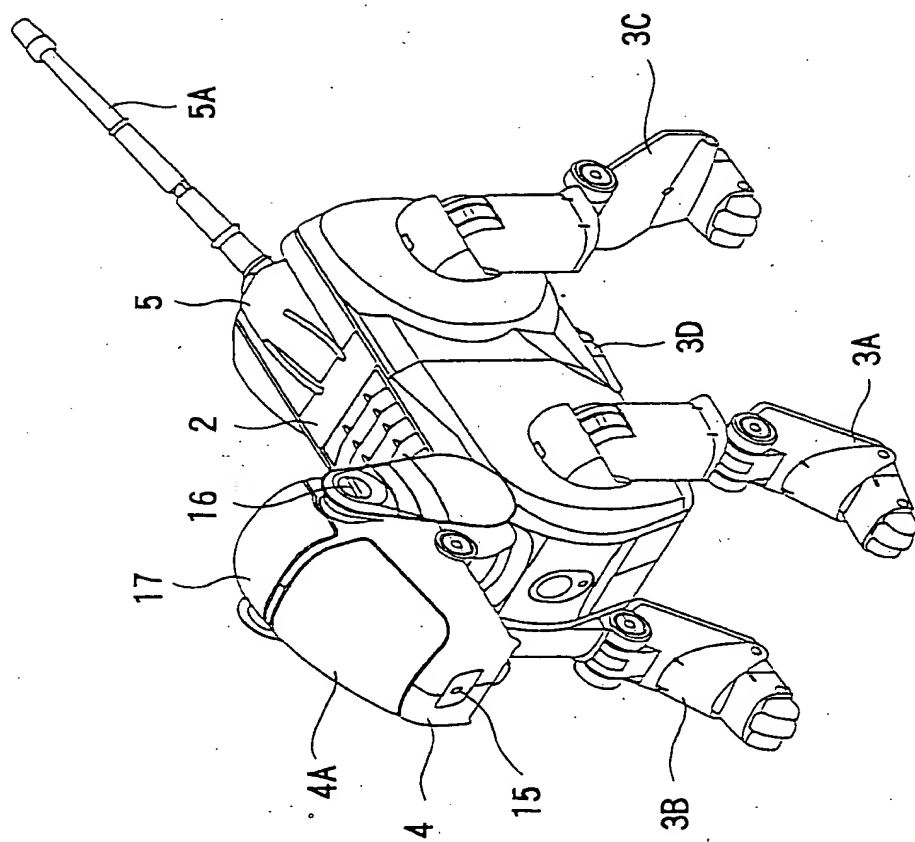


FIG. 1

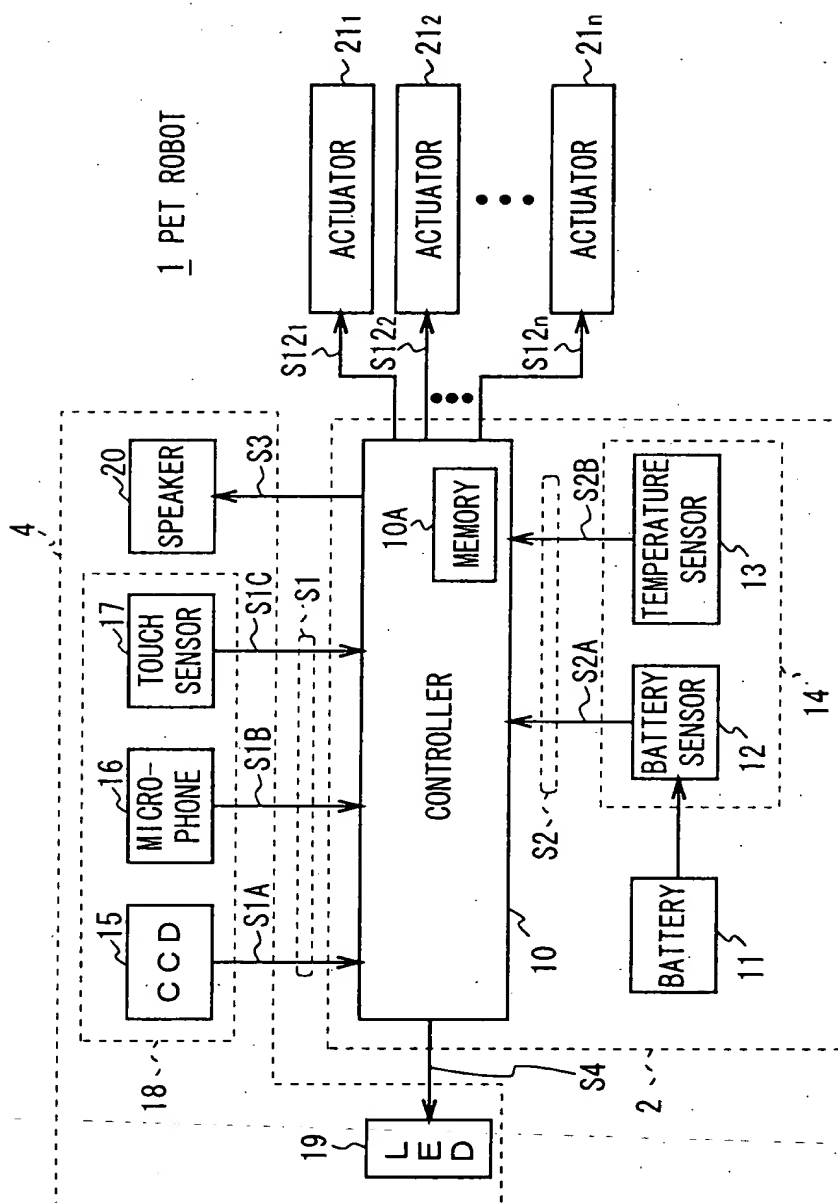


FIG. 2

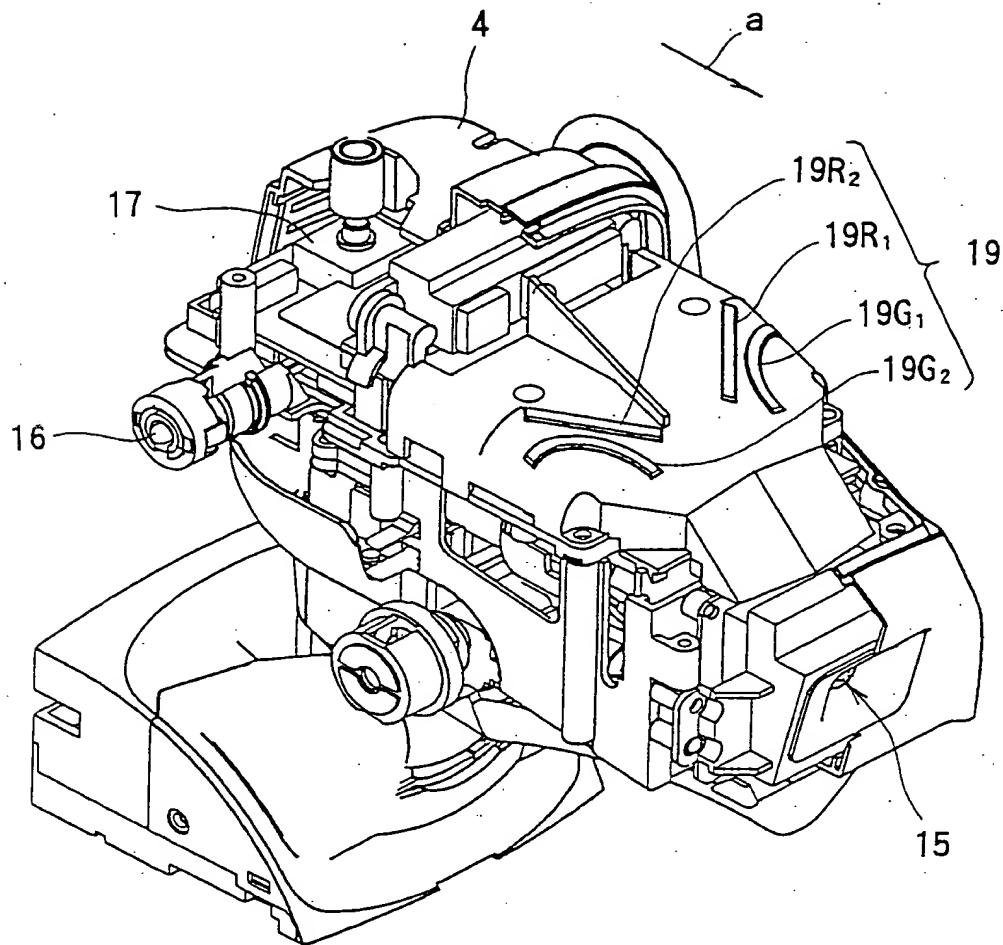


FIG. 3

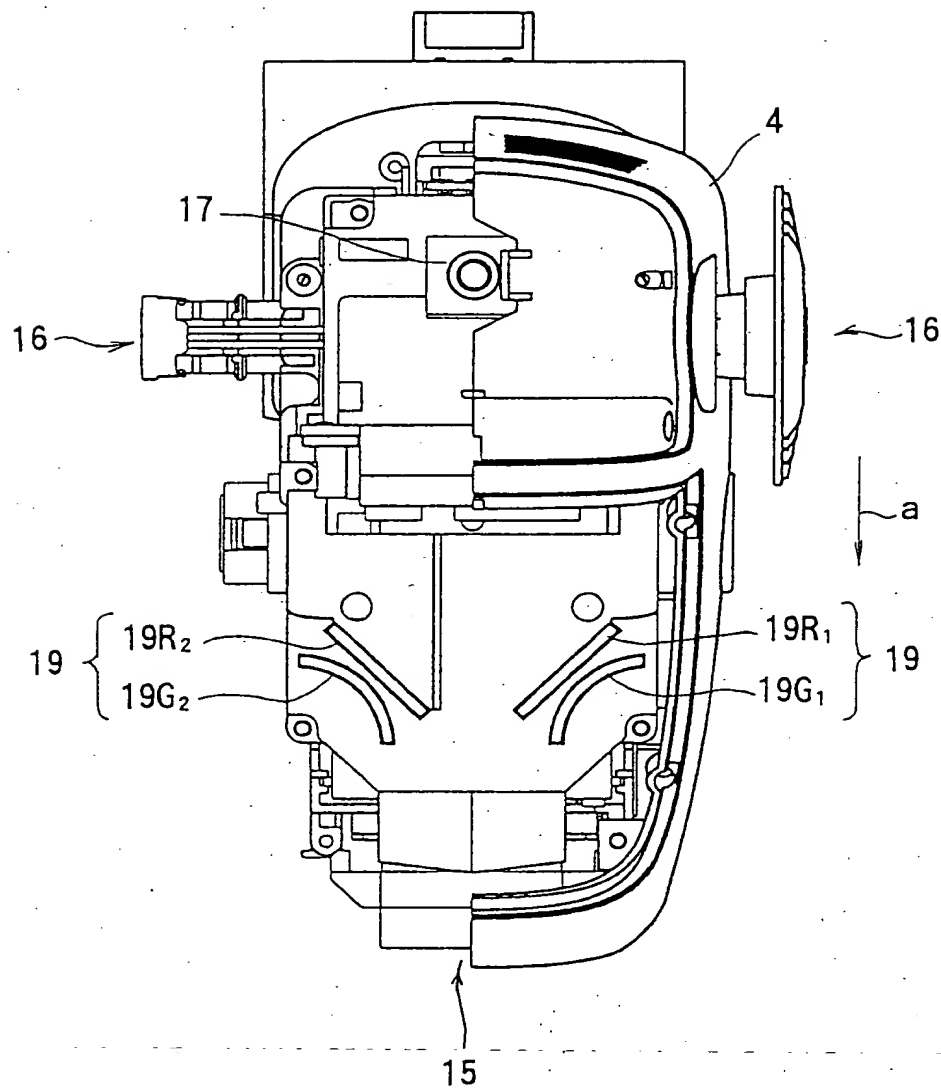


FIG. 4

FIG. 5

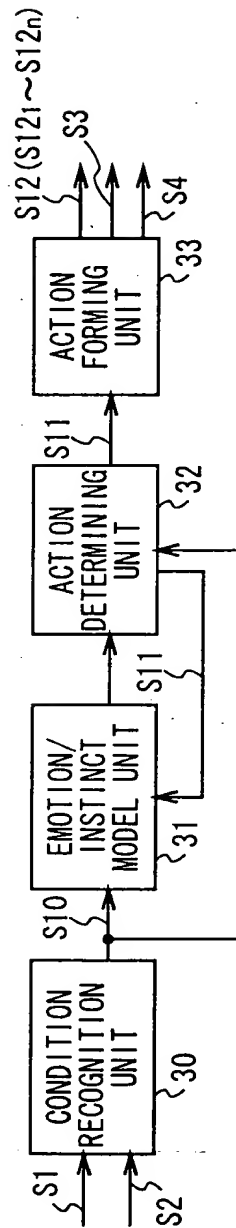


FIG. 5

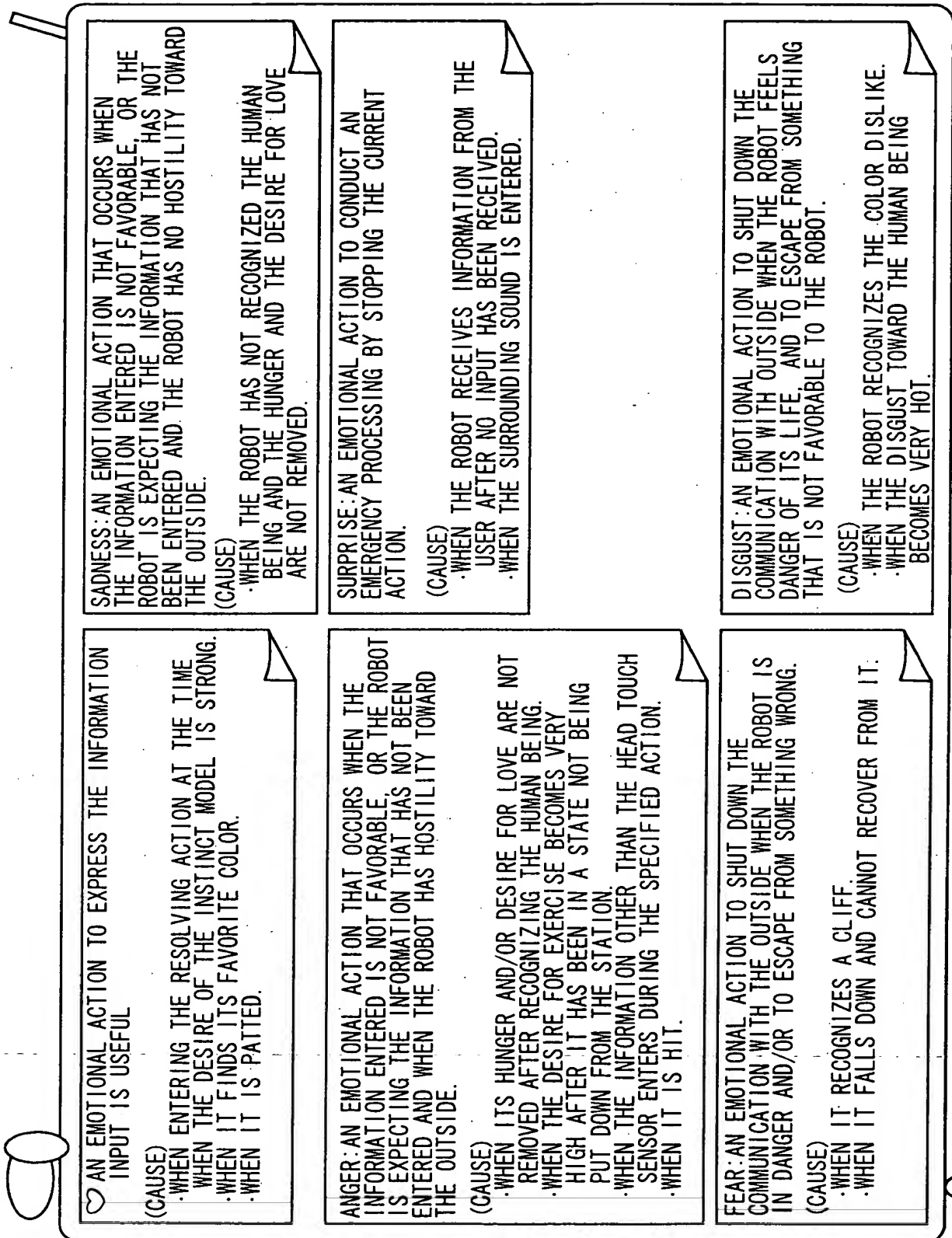


FIG. 6

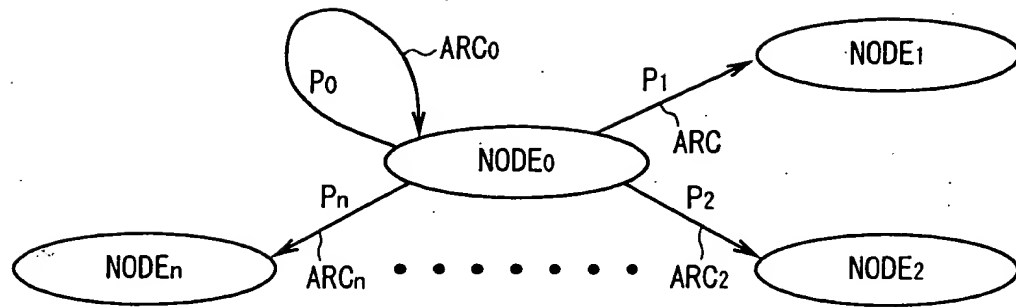


FIG. 7

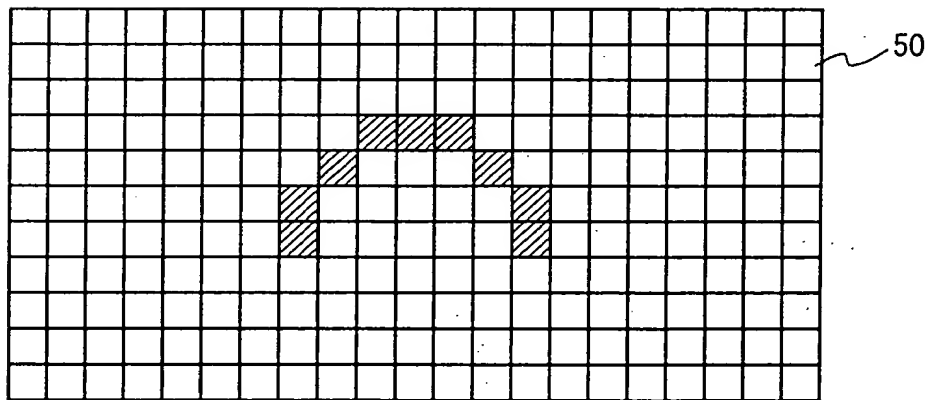


FIG. 9

NODE OF TRANSMITTING END OUTPUT ACTION	NAME OF INPUT EVENT		NAME OF DATA		RANGE OF DATA		TRANSITION PROBABILITY TO OTHER NODE				
							A	B	C	D	n
node 100							node 120 ACTION 1	node 120 ACTION 2	node 1000 ACTION 3		node 600 ACTION 4
1 BALL		SIZE		0, 1000		30%					
2 PAT							40%				
3 HIT									20%		
4 SOUND											50%
5 OBSTACLE		DISTANCE		0, 100							
6		JOY		50, 100							
7		SUPRISE		50, 100							
8		SADNESS		50, 100							

40

FIG. 8



## EXPLANATION OF REFERENCE NUMERALS

1 - PET ROBOT, 4 - HEAD UNIT, 4A - SEMI-TRANSPARENT COVER,  
10 - CONTROLLER, 10A - TOUCH SENSOR, 15 - CCD CAMERA, 16 -  
MICROPHONE, 17 - TOUCH SENSOR, 19R<sub>1</sub>, 19R<sub>2</sub> - RED LED, 19G<sub>1</sub>, 19G<sub>2</sub> -  
GREEN LED, 21<sub>1</sub> ~ 21<sub>N</sub> - ACTUATOR, 30 - CONDITION RECOGNITION UNIT,  
31 - EMOTION/INSTINCT MODEL UNIT, 32 - FACTION DETERMINING UNIT,  
33 - ACTION FORMING UNIT, 40 - CONDITION TRANSITION TABLE, S3 -  
AUDIO SIGNAL, S4 - LED DRIVING SIGNAL, S10 - CONDITION RECOGNITION  
INFORMATION, S11 - ACTION DETERMINING INFORMATION, S12 - DRIVING  
SIGNAL